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Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

Claims 1-34 (cancelled)

Claim 35 (new): A relative location data correction apparatus for correcting a shift of a location of a predetermined point, said location is relatively indicated as relative location data and said shift is a different between two map databases, said apparatus comprising:

a first shape data obtaining unit for obtaining first shape data from a first map database;

a relative location data creating unit for creating relative location data of an event occurrence point, wherein said relative location data indicates relative location to a node designated in said first shape data;

a second shape data obtaining unit for obtaining second shape data from a second map database, wherein said second shape data has a second point corresponding to said event occurrence point;

a first determining unit for determining a first total length of the first shape data; and

a second determining unit for a second total length of the second shape data; and

a correction unit for correcting said relative

location data by using said first total length and said second total length.

Claim 36 (new): The relative location data correction apparatus according to claim 35,

wherein said correction unit corrects the relative location data by using a ratio of said first total length to said second total length.

Claim 37 (new): A rrelative location data correction apparatus for correcting a shift of a location of a predetermined point, said location is relatively indicated as relative location data and said shift is a different between two map databases, said apparatus comprising:

a transmission apparatus including:

a first map database;

location expression conversion means for converting an event occurrence point into relative location data to a node designated in a first shape data, said first shape data is obtained from said first map database and represents the periphery of said event occurrence point; and

first total length determination means for determining a first total length of said first shape data;

wherein said transmission apparatus transmits said relative location data, and first shape data, and said

first total length, and

a reception apparatus including:

a second map database;

second total length determination means for determining a total length of a second shape data, which is obtained from said second map database and to which a second point corresponding to said event occurrence point belongs;

first relative location correction means for correcting said relative location data by using said first total length and said second total length; and

event occurrence point specification means for specifying location of said second point corresponding to said event occurrence point, based on said corrected relative location and said second shape data.

Claim 38 (new): A relative location data correction apparatus for correcting a shift of a location of a predetermined point, said location is relatively indicated as relative location data and said shift is a different between two map databases, said apparatus comprising:

a transmission apparatus including:

a first map database; and

location expression conversion means for converting an event occurrence point into relative location data to a node designated in a first shape data, based on

the first shape data obtained from said first map database and representing the periphery of said event occurrence point,

wherein said transmission apparatus transmits said relative location data and said first shape data, and

a reception apparatus;

first total length determination means for determining a first total length of said first shape data transmitted by said transmission apparatus;

a second map database;

second total length determination means for determining a second total length of a second shape data which is obtained from said second map database and to which a second point corresponding to said event occurrence point belongs;

first relative location correction means for corrects said relative location data by using said first total length and said second total length; and

event occurrence point specification means for specifying said second point corresponding to said event occurrence point, based on said corrected relative location data and said second shape data.

Claim 39 (new): The relative location data correction apparatus according to claim 37,

wherein said transmission apparatus further includes:

shape data compression/transformation means for creating a first processed shape data by an irreversible compression process said first shape data, or a shape transformation process of said first shape data;

first shape data decoding means for creating a third shape data by decoding said first processed shape data;

third total length determination means for determining a third total length of said third shape data; and

second relative location correction means for creating a second corrected relative location data by correcting said relative location data by using said first total length and said third total length,

wherein said transmission apparatus transmits said second corrected relative location data, said first processed shape data, and said third total length, and

wherein said reception apparatus further includes:

second shape data decoding means for decoding said first processed shape data,

wherein said first relative location correction means corrects said second corrected relative location data by using said third total length and said second total length.

Claim 40 (new): The relative location data correction

apparatus according to claim 38,

wherein said transmission apparatus further includes:

shape data compression/transformation means for creating a first processed shape data by performing an irreversible compression process of said first shape data, or a shape transformation process of said first shape data;

first shape data decoding means for creating a third shape data by decoding said first processed shape data;

third total length determination means for determining a third total length of said third shape data; and

second relative location correction means for creating a second relative location data by correcting said relative location data by using said first total length and said third total length,

wherein said transmission apparatus transmits said second corrected relative location data and said first processed shape data, and

wherein said reception apparatus further includes:

second shape data decoding means for creating a fourth shape data by decoding said first processed shape data; and

fourth total length determination means for determining a fourth total length of said fourth shape data,

wherein said first relative location correction means corrects said second corrected relative location data by using said second total length and said fourth total length determined by said third total length determination means and.

Claim 41 (new): The relative location data correction apparatus according to one of claims 37 to 40,

wherein said first shape data has a first feature node designated between nodes at both terminal ends of said first shape data,

wherein said second shape data has a second feature node corresponding to said first feature node, and

wherein said location expression conversion means converts said event occurrence point into a relative location data to said feature node.

Claim 42 (new): The relative location data correction apparatus according to claim 39,

wherein said first shape data has at least tow first feature nodes designated between nodes at both terminal ends of said first shape data,

wherein said second shape data has second feature nodes corresponding to said first feature nodes,

wherein said third shape data has third feature nodes corresponding to said first feature nodes,

if said event occurrence point is located between said first feature nodes and said second point is between said second feature nodes, wherein said first total length determination means calculates a total length of a distance between said first feature nodes, said second total length determination means calculates a total length of a distance between said second feature nodes, and said third total length determination means calculates a total length of a distance between said third feature nodes.

Claim 43 (new): The relative location data correction apparatus according to claim 40,

wherein said first shape data has at least tow first feature nodes designated between nodes at both terminal ends of said first shape data,

wherein said second shape data has second feature nodes corresponding to said first feature nodes,

wherein said third shape data has third feature nodes corresponding to said first feature nodes,

wherein said fourth shape data has fourth feature nodes corresponding to said first feature nodes, and

if said event occurrence point is located between said first feature nodes, wherein said first total length determination means calculates a total length of a distance between said first feature nodes, said second total length determination means calculates a total length of a distance

between said second feature nodes, said third total length determination means calculates a total length of a distance between said third feature nodes, and said fourth total length determination means calculates a total length of a distance between said fourth feature nodes.

Claim 44 (new): The relative location data correction apparatus according to one of claims 37 to 43,

wherein said each total length is determined with calculation or with reference to a predetermined value.

Claim 45 (new): The relative location data correction apparatus according to one of claims 41 to 44,

wherein said transmission apparatus further transmits shape data attribute information for identifying said each first feature node and indicating type of said each first feature node.

Claim 46 (new): The relative location data correction apparatus according to one of claims 41 to 45,

wherein said each first feature node is designated at a point whereat an angle difference in a predetermined area for a link constituting said first shape data is equal to or greater than a predetermined angle.

Claim 47 (new): A relative location data correction

method, for correcting a shift of a location of a predetermined point, said location is relatively indicated as relative location data and said shift is a different between two map databases, said method comprising the steps of:

obtaining a first shape data from a first map database;

creating a relative location data of an event occurrence point to a node in said first shape data;

determining a first total length of said first shape data;

obtaining a second shape data corresponding to said first shape data from a second map database;

determining a second total length of said second shape data; and

correcting said relative location data by using said first total length and said second total length.

Claim 48 (new): The relative location data correction method according to claim 47,

wherein, in the step of correcting said relative location data, said relative location data is corrected by using a ratio of said first total length to said second total length.

Claim 49 (new): A relative location data correction

method, for correcting a shift of a location of a predetermined point, said location is relatively indicated as relative location data and said shift is a different between two map databases, said method comprising the steps of:

obtaining a first shape data including an event occurrence point from a first map database;

converting a location expression of said event occurrence point into a relative location data to a node in the said first shape data;

determining a first total length of said first shape data;

transmitting relative location data for transmitting said relative location data, said first shape data, and said first total length;

obtaining a second shape data including a second point corresponding to said event occurrence point form a second map database;

determining a second total length of said second shape data; and

first correcting for correcting said relative location data by using said first total length and said second total length.

Claim 50 (new): A relative location data correction method, for correcting a shift of a location of a

predetermined point, said location is relatively indicated as relative location data and said shift is a different between two map databases, said method comprising the steps of:

obtaining a first shape data including an event occurrence point from a first map database;

converting a location expression of said event occurrence point into a relative location data to a node in the said first shape data;

transmitting for transmitting said relative location data and said first shape data;

determining a first total length of said first shape data;

obtaining a second shape data including a second point corresponding to said event occurrence point form a second map database;

determining a second total length of said second shape data; and

first correcting for correcting said relative location data by using said first total length and said second total length.

Claim 51 (new): The relative location data correction method according to claim 49, further comprising the steps of:

compressing/transforming for creating a first

processed shape data by performing an irreversible compression process said first shape data, or a shape transformation process of said first shape data;

a first decoding for creating a third shape data by decoding said first processed shape data;

a determining a third total length of said third shape data;

a second correcting for creating a second corrected relative location data by correcting said relative location data by using said first total length and said third total length; and

a second decoding for decoding a processed first shape data,

wherein, in the step of transmitting, said second corrected relative location data, said first processed shape data, and said third total length are transmitted, and

wherein, in the step of first correcting, said relative location data is corrected by correcting said second corrected relative location data by using said third total length and said second total length.

Claim 52 (new): The relative location data correction method according to claim 50, further comprising the steps of:

compressing/transforming for creating a first

processed shape data by performing an irreversible compression process of said first shape data, or a shape transformation process of said first shape data;

a first decoding for creating a third shape data by decoding said first processed shape data;

a determining a third total length of said third shape data;

a second correcting for creating a second corrected relative location data by using said first total length and said third total length;

a second decoding for creating a fourth shape data of decoding said first processed shape data; and

a determining a fourth total length of said fourth shape data,

wherein, in the step of transmitting, said second corrected relative location data and said first processed shape data is transmitted, and

wherein, in the step of first correcting, said relative location data is corrected by correcting said second corrected relative location data by using said second total length and said fourth total length.

Claim 53 (new): The relative location data correction method according to one of claims 49 to 52,

wherein said first shape data has a first feature node designated between nodes at both terminal ends of said

first shape data,

wherein said second shape data has a second feature node corresponding to said first feature node, and

wherein said location expression conversion means converts said event occurrence point into a relative location data to said feature node.

Claim 54 (new): The relative location data correction method according to claim 51,

wherein said first shape data has at least tow first feature nodes designated between nodes at both terminal ends of said first shape data,

wherein said second shape data has second feature nodes corresponding to said first feature nodes,

wherein said third shape data has third feature nodes corresponding to said first feature nodes, and

if said event occurrence point is located between said first feature nodes and said second point is between said second feature nodes, wherein a total length of a distance between said first feature nodes is determined as said first total length, a total length of a distance between said second feature nodes is determined as said second total length, and a total length of a distance between said third feature nodes is determined as said third total length.

Claim 55 (new): The relative location data correction method according to claim 52,

wherein said first shape data has at least tow first feature nodes designated between nodes at both terminal ends of said first shape data,

wherein said second shape data has second feature nodes corresponding to said first feature nodes,

wherein said third shape data has third feature nodes corresponding to said first feature nodes,

wherein said fourth shape data has fourth feature nodes corresponding to said first feature nodes, and

if said event occurrence point is located between said first feature nodes and said second point is between said second feature nodes, wherein a total length of a distance between said first feature nodes is determined as said first total length, a total length of a distance between said second feature nodes is determined as said second total length, a total length of a distance between said third feature nodes is determined as said third total length, and a total length of a distance between said fourth feature nodes is determined as said fourth total length.

Claim 56 (new): The relative location data correction method according to one of claims 49 to 55,

wherein said each total length is determined with

calculation or with reference to a predetermined value.

Claim 57 (new): The relative location data correction method according to one of claims 53 to 56,

wherein, in the step of transmitting, shape data attribute information for identifying said each first feature node and indicating type of said each first feature node are transmitted.

Claim 58 (new): The relative location data correction method according to one of claims 53 to 57,

wherein said each first feature node is designated at a point whereat an angle difference in a predetermined area for a link constituting said first shape data is equal to or greater than a predetermined angle.

Claim 59 (new): A relative location data correction program, which permits a computer to perform a relative location data correction method according to one of claims 47 to 58.

Claim 60 (new): A shape data generation apparatus for generating a shape data representing a predetermined section including an event occurrence point, said apparatus comprising:

a map database;

a map data obtaining unit for obtaining a map data covering an area where said event occurrence point exists;

a shape data obtaining unit for obtaining a shape data from said map data, wherein said shape data includes said event occurrence point;

a relative location data creating unit for converting a location expression of said event occurrence point into a relative location to a node in said shape data;

a feature node designating unit for designating a feature node which is a point in said predetermined section or in the periphery of said section and satisfies a predetermined condition; and

a shape data updating unit for updating said shape data so as to have said feature node, if said feature node is designated in the periphery of said section.

Claim 61 (new): The shape data generation apparatus according to claim 60, further comprising:

a nearest feature node obtaining unit for obtaining a feature node nearest to said event occurrence point; and

a location expression converting unit for converting said relative location data into a relative location to said nearest feature node.

Claim 62 (new): The shape data generation apparatus according to claim 60 or 61,

wherein, if a start point or an end point of said shape data is not suitable for the predetermined condition, said feature node determining unit checks whether a more suitable point than said start point or said end point exists in said shape data, and then determines said feature node in the vicinity of said start point or said end point.

Claim 63 (new): The shape data generation apparatus according to one of claims 60 to 62,

wherein said feature node designating unit designates plural feature nodes by selecting a point which is located within a predetermined distance from a previously selected point as a feature node and satisfies said predetermined condition, and repeating said selecting point along said shape data predetermined number of times.

Claim 64 (new): The shape data generation apparatus according to one of claims 60 to 63,

wherein said predetermined condition is that an absolute declination value at a point in a predetermined area between two continuous links characterized in that said point that satisfies said predetermined condition is a point for which an absolute declination value is equal to or greater than a predetermined value.

Claim 65 (new): A shape data generation method, for

obtaining map data from a map database and for generating a shape data representing a predetermined section, said method comprising the step of:

obtaining a map data covering an area where said event occurrence point exists;

obtaining a shape data from said map data, wherein said shape data includes said event occurrence point;

creating a relative location data by converting a location expression of said event occurrence point into a relative location to a node in said shape data;

designating a feature node which is a point in said predetermined section or in the periphery of said section and satisfies a predetermined condition; and

updating said shape data so as to have said feature node, if said feature node is designated in the periphery of said section.

Claim 66 (new): The shape data generation method according to claim 65, further comprising:

obtaining a feature node nearest to said event occurrence point; and

converting said relative location data into a relative location to said nearest feature node.

Claim 67 (new): The shape data generation method according to claim 65 or 66,

wherein, if a start point or an end point of said shape data is not suitable for the predetermined condition, in the step of determining feature node, checking whether a more suitable point than said start point or said end point exists in said shape data, and then determining said feature node in the vicinity of said start point or said end point.

Claim 68 (new): The shape data generation method according to one of claims 65 to 67,

wherein, in the step of designating feature node, plural feature nodes are designated by selecting a point which is located within a predetermined distance from a previously selected point as a feature node and satisfies said predetermined condition, and repeating said selecting point along said shape data predetermined number of times.

Claim 69 (new): The shape data generation method according to one of claims 65 to 67,

wherein said predetermined condition is that an absolute declination value at a point in a predetermined area between two continuous links characterized in that said point that satisfies said predetermined condition is a point for which an absolute declination value is equal to or greater than a predetermined value.

Claim 70 (new): A shape data generation program, which permits a computer to perform a shape data generation method according to one of claims 65 to 69.